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L17 and @pd > 20040928	0

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L18

Search History

DATE: Tuesday, May 31, 2005 [Printable Copy](#) [Create Case](#)

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<i>DB=TDBD; PLUR=NO; OP=OR</i>			
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<u>L17</u>	L16 AND (object ADJ model)	1	<u>L17</u>
<u>L16</u>	distance	4278	<u>L16</u>
<i>DB=JPAB; PLUR=NO; OP=OR</i>			
<u>L15</u>	L14 AND (object ADJ model)	0	<u>L15</u>
<u>L14</u>	L12 AND (distance ADJ object)same calculate	72	<u>L14</u>
<u>L13</u>	L12 AND (distance ADJ object)	2578	<u>L13</u>
<u>L12</u>	L11 AND (object near distance)	3633	<u>L12</u>
<u>L11</u>	L10 AND object	18999	<u>L11</u>
<u>L10</u>	distance	199562	<u>L10</u>
<i>DB=EPAB; PLUR=NO; OP=OR</i>			
<u>L9</u>	L8 AND calculate	12	<u>L9</u>
<u>L8</u>	L7 AND (object near distance)	389	<u>L8</u>

<u>L7</u>	distance aND object	3099	<u>L7</u>
<i>DB=USPT; PLUR=NO; OP=OR</i>			
<u>L6</u>	L3 AND (object near distance).ab.	1	<u>L6</u>
<u>L5</u>	L3 AND (object near distance)	39	<u>L5</u>
<u>L4</u>	L3 AND calculate	174	<u>L4</u>
<u>L3</u>	L2 AND (object OR class)	478	<u>L3</u>
<u>L2</u>	L1 AND distance	518	<u>L2</u>
<u>L1</u>	(717/103 717/108).ccls. OR (345/427 345/586 345/656 345/682 345/764).ccls.	1045	<u>L1</u>

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☐ 1. Document ID: WO 2005010552 A1

L9: Entry 1 of 12

File: EPAB

Feb 3, 2005

PUB-NO: WO2005010552A1

DOCUMENT-IDENTIFIER: WO 2005010552 A1

TITLE: DISTANCE MEASUREMENT METHOD AND DEVICE USING ULTRASONIC WAVES

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	KWIC	Draw De
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☐ 2. Document ID: WO 2079799 A1

L9: Entry 2 of 12

File: EPAB

Oct 10, 2002

PUB-NO: WO002079799A1

DOCUMENT-IDENTIFIER: WO 2079799 A1

TITLE: DISTANCE MEASURING DEVICE, DISTANCE MEASURING EQUIPMENT AND DISTANCE MEASURING METHOD

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	KWIC	Draw De
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☐ 3. Document ID: WO 9843111 A1

L9: Entry 3 of 12

File: EPAB

Oct 1, 1998

PUB-NO: WO009843111A1

DOCUMENT-IDENTIFIER: WO 9843111 A1

TITLE: METHOD FOR DETERMINING THE VERTICAL DISTANCE BETWEEN AN OBJECT AND A DEVICE WITH A VARIABLE POSITION

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	KWIC	Draw De
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☐ 4. Document ID: FR 2757640 A1

L9: Entry 4 of 12

File: EPAB

Jun 26, 1998

PUB-NO: FR002757640A1

DOCUMENT-IDENTIFIER: FR 2757640 A1

TITLE: Optical measurement system for speed or distance of object

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	KWIC	Draw De
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☐ 5. Document ID: EP 793117 A2

L9: Entry 5 of 12

File: EPAB

Sep 3, 1997

PUB-NO: EP000793117A2

DOCUMENT-IDENTIFIER: EP 793117 A2

TITLE: Light wave distance measuring apparatus and method for determining distance of an object

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	NUMC	Draw De
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☐ 6. Document ID: GB 2269015 A

L9: Entry 6 of 12

File: EPAB

Jan 26, 1994

PUB-NO: GB002269015A

DOCUMENT-IDENTIFIER: GB 2269015 A

TITLE: Apparatus for determining distances or dimensions

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	NUMC	Draw De
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☐ 7. Document ID: WO 9221181 A1

L9: Entry 7 of 12

File: EPAB

Nov 26, 1992

PUB-NO: WO009221181A1

DOCUMENT-IDENTIFIER: WO 9221181 A1

TITLE: DUAL SATELLITE NAVIGATION SYSTEM AND METHOD

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	NUMC	Draw De
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☐ 8. Document ID: WO 9219984 A1

L9: Entry 8 of 12

File: EPAB

Nov 12, 1992

PUB-NO: WO009219984A1

DOCUMENT-IDENTIFIER: WO 9219984 A1

TITLE: APPARATUS FOR LOCATING AN OBJECT, AND LIGHT TRANSMITTER

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	NUMC	Draw De
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☐ 9. Document ID: EP 474067 A2

L9: Entry 9 of 12

File: EPAB

Mar 11, 1992

PUB-NO: EP000474067A2

DOCUMENT-IDENTIFIER: EP 474067 A2

TITLE: Distance detecting apparatus.

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	KMC	Draw D
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☐ 10. Document ID: WO 9108440 A1

L9: Entry 10 of 12

File: EPAB

Jun 13, 1991

PUB-NO: WO009108440A1

DOCUMENT-IDENTIFIER: WO 9108440 A1

TITLE: PROCESS AND DEVICE FOR THE MEASUREMENT OF DISTANCES IN GASES AND LIQUIDS
USING ULTRASONICS

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	KMC	Draw D
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☐ 11. Document ID: EP 419082 A2

L9: Entry 11 of 12

File: EPAB

Mar 27, 1991

PUB-NO: EP000419082A2

DOCUMENT-IDENTIFIER: EP 419082 A2

TITLE: Optical gauging apparatus.

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	KMC	Draw D
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☐ 12. Document ID: DE 3401919 A1

L9: Entry 12 of 12

File: EPAB

Jul 25, 1985

PUB-NO: DE003401919A1

DOCUMENT-IDENTIFIER: DE 3401919 A1

TITLE: Camouflage projector

Full	Title	Citation	Front	Review	Classification	Date	Reference			Claims	KMC	Draw D
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L9: Entry 3 of 12

File: EPAB

Oct 1, 1998

PUB-NO: WO009843111A1

DOCUMENT-IDENTIFIER: WO 9843111 A1

TITLE: METHOD FOR DETERMINING THE VERTICAL DISTANCE BETWEEN AN OBJECT AND A DEVICE WITH A VARIABLE POSITION

PUBN-DATE: October 1, 1998

INVENTOR-INFORMATION:

NAME

COUNTRY

FLEISCHHAUER, NORBERT

DE

HASSLER, GREGOR

DE

ASSIGNEE-INFORMATION:

NAME

COUNTRY

MANNESMANN VDO AG

DE

FLEISCHHAUER NORBERT

DE

HASSLER GREGOR

DE

APPL-NO: EP09801548

APPL-DATE: March 18, 1998

PRIORITY-DATA: DE19711467A (March 20, 1997)

INT-CL (IPC): G01 S 15/93

EUR-CL (EPC): G01S015/42; G01S015/87, G01S015/93

ABSTRACT:

CHG DATE=19990905 STATUS=O>The invention relates to a method for determining the vertical distance between an object and a device with a changing position, especially a motor vehicle, whereby a first sensor placed in this device gives off a signal, said signal is reflected by the object, and the reflected signal is received by the first sensor. The distance between the first sensor and the object is calculated from the transit time of the signal from being sent to being received by the first sensor. This distance is used to calculate all possible positions of the object in relation to the sensor, in order to determine the vertical distance of the object. The signal reflected by the object is also received by a second sensor, this second sensor also being positioned in the device with a variable position. A path from the first sensor to the object and from the object to the second sensor is then calculated from the transit time of the signal from the first sensor to the second sensor. This path is used to determine all possible positions of the object in relation to the second sensor. Finally, the positions calculated for the first and second sensors with the same distance are compared and the vertical distance to the device with a variable position is determined for the positions of the object detected by both the first and second sensors.

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